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A System for lighting of an object

[Technical Field]

The invention ~~deals with~~ relates to navigational engineering, more specifically, ~~optical~~ electronic systems for autotracking of moving objects.

Known in the present state of art

[Background Art]

There are systems for automatic guidance and tracking of moving targets, which are based on the frequency, phase, pulse-height, time-pulse and amplitude-phase principles and can be used for illumination of objects [1].

Known coordinators (target seekers) generate signals, which are proportional to the constituents of the angle of misalignment in two mutually perpendicular planes of control. These signals go to the monitoring drive of the system for target autotracking, which keeps the coordinator's optical system operating in a mode to have the optic axis constantly directed towards a target.

~~One of the reasons that prevent from obtaining the undermentioned technical result by the known device is the fact that modulation of the radiant flux is performed mechanically with the help of a modulating disk which is disposed in the focal plane of a lens and rotated by an electric motor with a constant speed, the known system fails to provide high accuracy of measuring angular coordinates of the target.~~

Insofar as aid at

There also exists a two-gimbal suspension with a diverting mirror for a precision optical tracking system developed by the TRW firm and intended to be used as part of an optical tracking system [2].

This device consists of a gimbal joint of flexible suspension, four electrodynamic drives, a caging gear, a device of signal leveling for integration with a capacitive pickup of the shift, and an electronic unit. A capacitive sensor serves for generating signals of angular misalignment along two axes.

On both sides of the outer gimbal ring there are two actuators of the detention system.

Mobile electromechanical clusters cause low reliability and low-speed response of the above-mentioned coordinators.

Besides, their construction does not allow directing mirror-reflected beams along their optic axes and, moreover, these target seekers are capable of tracing targets only within the immediate field of their vision and stop operating when the target is not seen, for they are not designed for operating in the search mode.

The ~~closest~~ ^(the prototype) proposed invention as to a combination of features is a device of the same intent as the presentational invention in what concerns the complex of its characteristics is a system for location of two-dimensional coordinates of an object (a target seeker) [3]. The prototype has the first and the second ruled ^{optoelectronic} optical-electronic converters (OEC) with the image-transforming optics; the inputs of these converters are connected to the output of the synchro generator, while their outputs, to the inputs of the corresponding search signal detectors (threshold elements).

The ruled OECs are mutually perpendicular, so that rotation axes of the objects should pass through optical ^{centers} centres of the cylinder lenses L_1 and L_2 .

On mutual lag (misalignment) of the strobe pulse and the target signal, control signal conditioners CSE_1 and CSE_2 produce control signals, whose signs and values are proportional to the angular coordinates of the target in two mutually perpendicular planes of control.

Yet, the known ^{optoelectronic} optical-electronic target seeker does not permit to point the beam at an object and seek for a target if the object is beyond its field of vision.

^{present} ^[Summary of the Invention] The purpose of the presentational invention consists in diversifying functions said system ensuring a higher measuring accuracy of the angular coordinates of a target due to beam pointing at the center of the target image. One more object of the invention is to extend the functional capabilities of the system → outer space.

The implementation of this invention will technically result in more precise for lighting an object comprising a first guidance device further comprises a measuring of angular coordinates of a target because now the beam is pointed at the centre of the target image.

This technical result is achieved with the help of such elements installed in the first device of the object guidance, as the additional second guidance device

optically connected ~~with~~^{to} the source of radiation, the first and the second subtracting amplifiers, the first and the second ~~actuator~~^{actuators}, the first and the second actuator and a mirror. The first outputs of the first and the second guidance devices are connected to the corresponding inputs of the first subtracting amplifier, while their second outputs, ~~to~~ to the corresponding inputs of the second subtracting amplifier. The outputs of the first and the second subtracting amplifier are connected to the inputs of the corresponding actuators kinematically ~~linked~~^{coupled} to the mirror.

The first and the third guidance devices are of identical circuit design and actuate ~~electrically linked to each other~~ the target seeker (TS), the search signal conditioner (SSC), the first and the second angular position pickups (APP₁, APP₂), commutators, the third and the fourth actuators (A₃, A₄), ~~kinematically linked with~~^{cinematically to} a target seeker, and the angular position pickups, all other being electrically connected to one another.

[Brief Description of the Drawings]

Further objects and advantages of the present invention will become obvious from a detailed description of the system for lighting an object and the accompanying drawings, wherein:

- 1 - object;
- 2 - radiation source;
- 3, 4 - (1, 2 respectively) guidance device;
- 5, 6 - (1, 2 respectively) subtracting amplifier;
- 7, 8 - (1, 2 respectively) actuators;
- 9 - the first mirror;
- 11 - normal to the surface of the mirror 9 in the origin of the coordinate system OXYZ;
- 9¹ - the second mirror;
- 10 - commutation unit;
- 11, 12 - (3, 4 respectively) actuators;
- 13 - the third guidance device (GD₃);
- 14 - laser excitation circuit.

Figure 2 shows the functional diagram of the commutation unit (CU10) where:

- 15, 16 - (1, 2 respectively) commutators;

- 17 - the first radio receiver with an aerial (AR);
- 18 - three contact four position radio-controlled switch;
- 19 - source of unit voltage $+V_1$;
- 20 - the first "I₁" element;
- 21 - the first inverter;
- 22 - radio transmitter;

V_{inp1}, V_{outp2} - the first and the second output;

$V_3, V_4, V_3^I, V_4^{II}$ - the third - sixth input;

$A_1, A_2, A_3, A_4 + V_1$ - the first-fifth respective commutation unit output.

Figure 3 shows the block diagram of the first (third) guidance devices (3,13); where:

- 23^I - the first (third) target seeker TS₁;
- 24 - the first (third) light marker (corner-reflector) LM₁^I (LM₁^{III});
- 25, 26 - (5,6 respectively) actuators A₅^I, A₆^I, A₅^{III}, A₆^{III};
- 27, 28 - (1, 2 respectively) angular position pickups;
- 29, 30 - (3, 4 respectively) commutators (C₃^I, C₄^I, C₃^{III}, C₄^{III});
- 31 - the first (third) search signal conditioner (SSC).

Figure 4 shows the block diagram of the second guidance device GD₂, used in the system;

where:

- 32 - the second target seeker TS₂;
- 33 - the second light marker LM₂ (the second corner-reflector CR₂);
- 34, 35 - (7, 8 respectively) actuators (A₇, A₈);
- 36, 37 - (3, 4 respectively) angular position pickups (APP₃, APP₄);
- 38, 39, 40, 41, 42, 43, 44 - (5, 6, 7, 8, 9, 10, 11 respectively) - commutators;
- 45 - the second search signal conditioner (SSC₂);
- 46 - commutation input of the second guidance device (GD₂).

Figure 5 shows the pulse laser excitation circuit 14, where:

- 47 - the second radio receiver;
- 48 - remote radio-controlled switch;

- 49 - the second source of unit voltage $+V_2$;
- 50 - the excitation circuit output;
- 51 the second "I₂" element;
- 52 the second inverter (HF₂);
- 53 - the third "I₃" element.

Figure 6 shows the construction of ~~the second film mirror 9¹~~, where:

- 54 - locating ring with limiters;
- 55 - internal pneumatic chamber consisting of 2 sections;
- 56 - external pneumatic chamber;
- 57 - radial tubes (hoses);
- 58 - the first elastic reflecting sheet;
- 59 - dielectric film;
- 60 - metal layer;
- 61 - source of compressed gas (SCG);
- 62 - the second elastic reflecting sheet;
- 63 - source of vacuum (pump);
- 64 - emf source;
- 65 - isolated rings;
- 66 - sources of controlled voltage;
- 67 - corrugated elastic band;
- 68 - the third pneumatic chamber;
- 69 - hose (gas conduit);
- 70 - clamp-shaped spring;
- 71 - valves.

- Detailed description -
- Insert paragraphs A ~~and B~~ ^{and C} Attached

Figure 7 ~~shows~~ presents combined kinematic and optical schemes of the system, in which the first target seeker (TS₁)^{23¹} of the first guidance device GD₃ makes the search of an object 1 with the help of the first 72 and the second 73 bracket of the actuators A₅ and A₆ (servomotors 25¹, 26¹), whose angular positions are determined by angular position pickups (APP¹ and APP²) (synchro transmitters or

INSERT A

Detailed Description of the Invention

The system for lighting an object 1 (FIG.1) comprises a radiation source 2 and guidance devices 3, 4, 5, of which the guidance device 3 is optically connected to the object 1, and the device 4, to the radiation source 2. The system further comprises a subtracting amplifier 6 having its inputs 7 and 8 connected to the respective outputs of the guidance devices 3 and 4, while the output thereof is connected to an input 9 of the commutation unit 10, and a subtracting amplifier 11 whose inputs 12 and 5 are connected to the outputs of the guidance devices 3 and 4, respectively, and its output is connected to an input 14 of the commutation unit 10. Inputs 15 and 16 of the commutation unit 10 are connected to the corresponding outputs of the guidance device 3, while its inputs 17 and 18 thereof are connected to the respective outputs of the guidance device 4. In addition, the system comprises a mirror 19 with which kinematically coupled are actuators 20 having their inputs connected to an output 23 of the commutation unit 10, as well as a mirror 19 with which kinematically coupled are actuators 46 connected to an output 47 of the commutation unit 10 and actuators 48 having their inputs connected to an output 49 of commutation unit 10. An output 51 of commutation unit 10 is connected to the input of the guidance device 4. The radiation source 2 is a laser disposed on guidance device 5 and connected to a laser excitation circuit 52 whose input

are connected to the respective outputs of the guidance device 5.

The commutation unit 10 comprises commutators 31 and 53
(FIG.2) having one of the inputs thereof serving as respective
inputs 15, 47, 9, and 14 of commutation unit 10, a radio receiver
33 with an antenna A, said receiver being connected to three
contacts 55, 56, and 36 of a four-position radio-controlled switch
37 through which an output 21 and the output 47 of the commutation
unit 10 are connected to the output of the commutator 31, and the
output 23 and an output 49 of the commutation unit 10 are connected
to the output of the commutator 53. The commutation unit 10
comprises also a unit signal source 59 whose output being
connected, when the contacts 55, 56, 36 of the switch 37 in
position IV, to the output 51 of the commutation unit 10, and when
the switch in position III, to parallel-connected inputs 60 and 61
of the respective commutators 31 and 53. In addition, the contacts
56 and 36 of the contacts 55, 56, 36 of the switch 37 with its
being in positions II, III, and IV are parallel-connected. The
commutation unit 10 further comprises an AND gate 62 having its
inputs connected to the inputs 9, 14, 15, 16, 17, and 18 of the
commutation unit 10, and its output connected, through an inverter
63, to a radio transmitter 64.

FIG.3 presents a block-diagram of the guidance device 3 or 5,
each comprising kinematically coupled a target seeker 44 carrying

a light marker 66 (or corner reflector), actuators 46 and 47, and angular position pickups 48 and 49 whose outputs are in fact the respective outputs of the guidance device 3 or 5. The pickups 48 and 49 may appear as, e.g., synchro transmitters or potentiometers.
Furthermore, each guidance device 3 or 5 comprises a search signal conditioner 50 connected respectively through its outputs to the outputs of the target seeker 44, one of said outputs serving as respective outputs of the guidance device 3 or 5. One of the outputs of the search signal conditioner 50 is connected to one of the inputs of a commutator 60, its second output, to one of the inputs of a commutator 61, and a third output of the search signal conditioner 50 is connected to the parallel-connected other inputs of the commutators 60 and 61 whose outputs are connected to the inputs of the actuators 46 and 47. Besides, one of the inputs of the commutators 60 and 61 are connected to respective outputs of the target seeker 44.

The guidance device 4 (FIG.4) comprises kinematically coupled a target seeker 53 carrying a light marker 54 (or corner reflector), actuators 55 and 56, and angular position pickups 57 and 58 whose outputs are in fact the respective outputs of the guidance device 4, as well as commutators 59, 60, 61, 62, 63, 64, and 44 and a search signal conditioner 66. One inputs of the commutators 59, 60, and 61 are connected to the corresponding outputs of the target seeker 53, while the other inputs of said

commutators are parallel-connected to the corresponding inputs of the commutators 64 and 44 and serve in fact as the commutation input of the guidance device 4. In addition, the outputs of the commutators 59, 60, and 61 are connected respectively to the inputs of the search signal conditioner 66 two outputs of which are connected to the corresponding inputs of said commutators, and a third output thereof is connected to the parallel-connected inputs of said commutators 62 and 63. Other inputs of the commutators 62 and 63 are connected to the outputs of the commutators 64 and 44 whose inputs are connected respectively to the outputs of the target seeker 53.

FIG.5 displays a pulsed laser excitation circuit, comprising a radio receiver 67 with an antenna, a remotely controlled switch 68 connected to the output of a unit signal source 69, as well as series-connected AND gate 70, NOT (inverter) gate 71, and an AND gate 109. One of the inputs of the AND gate 109 is connected, via the switch 68, to the output of the unit signal source 69, while the output of the AND gate 109 is in fact the output of the laser excitation circuit 52 (FIG.1). Besides, the inputs of the AND gate 70 (FIG.5) are in effect the inputs of the laser excitation circuit 52 (FIG.1) connected to the outputs of the guidance device 5.

The film mirror 19 (FIG.6) comprises a locating ring 110 with limiters, an internal pneumatic chamber 74 and external pneumatic

chamber 75 communicating with each other through radial tubes 76 appearing as, e.g., hoses, as well as with a source 77 of compressed gas through a gas conduit 78 appearing as, e.g., a hose wherein a valve 79 is provided. The pneumatic chambers 74 and 75 and radial tubes 76 are associated with an elastic reflecting sheet 106 consisting of an elastic dielectric film 107 to which a light-reflecting metallic (e.g., aluminum) layer 109 is applied.

The film mirror 19 may further comprise an elastic reflecting sheet 110 which is positioned at a specified distance from the reflecting sheet 106, while the metallic layers of the sheets 106 and 110 are connected to the opposite poles of an emf source 111. The reflecting sheets 106 and 110 together with the pneumatic chambers 74 and 75 establish a pressure-tight low-pressure cavity communicating with a source 112 of vacuum.

Furthermore, the internal pneumatic chamber 74 may made up of two pneumatically intercommunicating sections interconnected by a corrugated band so as to be mutually displaceable, and the metallic layer of the reflecting sheet 110 may appear as concentric rings 87 insulated from each other and connected to sources 108 of controlled voltage. A spring shaped as a clamp 89 is put from above onto the corrugated band 86, and a pneumatic chamber 90 is placed in the interior space of said spring and communicating, via an individual gas conduit 91, to the source 77 of compressed gas.

FIG. 7 presents combined kinematic and optical diagrams of the system, wherein the target seeker 44 of the guidance device 3 makes the search of an object 1 with the aid of brackets 109 and 110 of the actuators (servomotors) 46 and 47 whose angular positions are determined by the angular position pickups (synchro transmitters or potentiometers) 48 and 49. The target seeker 53 is directed towards the source of radiation (the Sun) by brackets 94 and 95 mechanically associated with the respective shafts of the actuators (servomotors) 55 and 56 whose angular positions are determined by the angular position pickups of the guidance device 4.

The mirror 19 is installed on an internal frame 96 of a first gimbal mount whose external frame 97 is kinematically coupled to the actuators 22.

The mirror 19 is installed on a second gimbal mount composed of an internal frame 98 and an external frame 99, respectively, and is held in position on the ring 110 which in turn is locked-in with the external frame 99 of the second gimbal mount whose position with respect to the internal frame is adjustable with the aid the actuators (servomotor) 46. The internal frame 98 is adjustable for position with respect to the gyro-stabilized platform with the aid of the actuators 48.

FIG.8 shows various positions of the mirror 19 (j1 - j2) rotating about its own axis, relative to the Earth 100.

The search signal conditioner 50 or 66 (FIG.9) comprises a logic element (gate) 101 whose inputs 102, 103, and 104 serve as the inputs of the search signal conditioner 50 or 66, of which the input 104 is a sync input. The search signal conditioner 50 or 66 further comprises a generator 105 of linearly varying voltage, said generator having its zeroing input connected to the output of the logical unit 101 and its output, to the parallel-connected control inputs of amplitude modulators 106 and 107 whose other inputs are connected to the respective outputs of a quadrature generator 108 and the outputs of said modulators are connected respectively to one inputs of summers 109 and 110 the other inputs of which are connected to the respective outputs of sampling-and-storage devices 111 and 112 whose data inputs are connected to the outputs of the summers 109, 110 which are also connected to the inputs of analog-to-digital converters 15 and 114, respectively. The record permitting inputs of the sampling-and-storage devices 111 and 112 are connected in parallel to each other and also connected to the output of the logical unit 101. The outputs of the analog-to-digital converters 15 and 114 and the output of the logical unit 101 are in fact the respective outputs of the search signal conditioner 50 or 66.

FIG.10 displays a functional diagram of the logical unit 101 which comprises inverters 115 and 116 whose outputs are connected to the respective sync set inputs of flip-flops 117 and 118 having their outputs connected to the D-inputs of flip-flops 119 and 120. The C-inputs of the flip-flops 117 and 118 are integrated and connected to the output of an inverter 121 whose input is connected to the C-inputs of the flip-flops 117 and 118. The logical unit 101 further comprises an AND gate 122 connected through its inputs respectively to the outputs of the flip-flops 119 and 120, the output of said AND gate 122 is also the output of the logical unit 101. The inputs of the inverters 115 and 116 are the respective inputs of the logical unit 101, and the input of the inverter 116 is in fact the sync input thereof.

potentiometers) 27' and 28'. The second target seeker 23¹¹ of the second guidance device is directed towards the source of radiation (the Sun) by the third 74 and the fourth 75 bracket, mechanically attached to the corresponding shafts of the actuators A₃ 34 and A₄ 35 (servomotors), whose angular positions are determined with the help of the third (APP₃ 36) and the fourth (APP₄ 37) angular position pickup of the second guidance device 4.

The second mirror 9¹ is established on the gimbal mount, which consists of an internal 76 and external 77 frame.

The second mirror 9¹ is rigidly fixed on the ring 54, which, in its turn, is rigidly attached to the external frame of the gimbal mount 77, whose position with respect to the internal frame 76 is changed with the help of the third actuators A₃ (the servomotor) 11. Position of the internal frame 76 with respect to a gyro-stabilised platform is changed with the help of the fourth actuators A₄ 12.

Figure 8 shows different positions of the mirror (9¹) rotating about its axis in relation to the Earth 78;

Figure 9 shows the functional flow chart of the searching signals conditioners; and (SSC₁ 31, SSC₂ 65), where 79 is a generator of linearly changing voltage (GLCV), whose output is connected to the controlling inputs of the first 80 and the second 81 amplitude modulator (M₁, M₂). The modulators' outputs are connected to the first inputs respectively of the first 82 and the second 83 summer (Σ₁, Σ₂). The second inputs of the summers, in their turn, are connected to the outputs respectively of the first 84 and the second 85 storage sampling device (SSD₁, SSD₂), while their outputs - to the inputs respectively of the first 86 and the second 87 analogue-digital converter (ADC₁, ADC₂). 88 is a quadrature generator (G); 89 - a logical unit (LU), the inputs of which are respectively the first 90, the second 91 and the sync input 92 of the search signal conditioner SSC₁ 31, SSC₂ 45, while 93 and 94 are respectively its first and second output.

Figure 10 gives the functional diagram of the logical unit 89, where 90, 91, and 92 are the first, the second and the sync input; 95 and 96 - the first and the

~~second inverter (HE₃, HE₄)~~, whose outputs are connected respectively to the setting to unity sync inputs of the first 97 and the second 98 flip-flop, with their outputs connected to the D-inputs of the corresponding third 99 and fourth 100 flip-flop; ~~their outputs~~, in turn, are connected to the inputs of the fourth "I" element 101, C-inputs of the first two flip-flops (FF₁, FF₂) are paralleled and connected to the output of the fourth inverter 102. The fourth "I" 101 element's output is the output +03 of the logical unit 89. [SEE INSERTA] - Entitled "Detailed Description of the Invention" attached

The system for lighting of an object operates as follows.

For illumination of cities situated in the area of middle latitudes and at the equator, the system for illumination should be installed on a ~~gyrostabilized~~ platform placed in a stationary orbit with an altitude about 36,000 km. Fixity of the satellite, which is carrying the system of the mirror guidance, in relation to the ground object adds to the advantages of the project.

High altitude of the stationary orbit permits to light a number of selected ground objects with the ~~help~~^{aid} of a single system.

From a satellite in the stationary orbit a vast area of the Earth can be seen that extends for $\pm 60^{\circ}$ from the west to the east and for $\pm 70^{\circ}$ from the north to the south.

Emergency illumination of objects in case of natural disasters and catastrophes is secured by three systems, which are removed from each other for 120° along the equator and completely embrace the Earth surface, except for the polar areas.

A satellite in the stationary orbit is almost constantly illuminated by the Sun. Its stay in the Earth shadow takes not more than 1% of the earth-rotation period, which determines high potency of the system.

While tracking, the mirror turns through 45° in 6 hours, that is, it rotates at the angular velocity of $\varphi' = 7.5'$ /min (minutes of arc per minute).

The whole system can be supplied with power by solar batteries, which are permanently directed towards the Sun by the second guidance device GD₂ 4, (FIG.1).

Directing sensors usually consist of two sensing elements, electrically linked into a bridge circuit. Together with them, the system of solar orientation includes an all-round looking sensor to produce information to a low degree of accuracy sufficient for more precise sensors of the guiding device 4 to direct their fields of vision towards the Sun.

The system for lighting of an object is established on a ~~gyrostabilised~~
^{spacevehicle} platform of a space vehicle (SV). Every problem of the ~~SV~~
^{a spacevehicle} flight control is handled by the control system. Together with the problem of an ~~SV~~
^{guidance devices 3 and 4} attitude-control and ~~stabilization~~
^{stabilisation}, it is guidance of the ~~GD₁~~ and ~~GD₂~~ towards different objects in response to a command from the Earth.

Signals, qualifying physical parameters of the flight, are received from the system of sensors.

Sensors of direction are used for attitude control. ~~Stabilisation~~
^{Stabilization} of the ~~SV~~
^{spacevehicle} is performed by signals from the sensors of direction and by signals of gyroscopic pickups, which register position of the axes in space.

Reference parameters of the ~~SV~~
^{spacevehicle} flight can be loaded into the storage of an onboard computer, transmitted aboard by the ground stations through a command radio line or withdrawn from the pickups of the ~~gyro~~
^{stabilized} stabilised platform.

Comparison of actual flight parameters with the reference ones, detection of error signals and generating of correcting control signals are performed by an onboard computer.

The ~~second~~
¹⁹ mirror ~~9~~
^{aid} is rotated about two orthogonally related axes OX and OY with the help of the actuators ~~A₃~~
⁴⁶ and ~~A₄~~
⁴⁸. A change in the attitude of the locating ring ~~54~~
¹¹⁰ is followed by the change in the attitude of the ~~second~~
¹⁹ mirror. The external frame ⁹⁹ of the ^{second} ring-shaped gimbal mount ~~77~~
^{fitted} ¹¹⁰ is fit with the locating ring with limiters ~~54~~
⁷⁴ and the internal pneumatic chamber ~~55~~
⁷⁶. This chamber is pneumatically connected by radial tubes (hoses) ~~57~~
⁷⁵ with the concentric external pneumatic chamber ~~56~~
⁷⁷ and together with it makes a single pressure-tight cavity, which is jointed up to a source of compressed gas (SCC) ~~61~~
⁶⁰. In transit, the chamber is empty.

and may be folded. Gas delivery will make the chamber take the form of a wheel.

The external ring ⁵⁶ can be a few tens of kilometres in radius. In advance, when still on the ground, the reflecting sheet ⁵⁸ is attached to the pneumatic chambers ⁷⁴ ⁷⁵ ⁵⁵, ⁵⁶. With gas delivery from the source ~~SCG~~ ⁷⁷ ⁶¹, the external ring ⁵⁶ starts pulling the ~~first~~ ¹⁰⁶ reflecting sheet ⁵⁸. The pneumatic chambers finally having taken the form of the wheel, the reflecting sheet ⁵⁸ ¹⁰⁶ should take the form of a plane.

For attainment of strength, the sheet can have a kapron warp coated with ^{the} dielectric film (e.g., ¹⁰⁷ fluorinated ~~fluorine~~ plastic), ^{to} on which a reflecting metal coating ¹⁰⁹ (e.g., aluminium) is applied.

When filled with gas, the collapsible ^{radial} hoses ⁵⁷ take the form of tubes. They, to some extent, reinforce the pneumatic wheel (see Fig. 6). This is how the second mirror ⁹ is constructed. With the help of the third ¹¹ and the fourth ¹² actuators the second mirror ⁹ is rotated about the axes OX and OY to direct the reflected sunrays towards a ground object.

Because the solar disk has ~~a~~^{an} angle of view, rays reflected by the mirror diverge and illuminate the ground area considerably exceeding that of the mirror.

The second mirror ¹⁹ may be given a spherical (concave) form. This allows ^{one} to concentrate sunrays on a small area and, thus, to increase the illuminance. For the purposes of ^{defense}, the focused sunrays can be used for setting fire to the enemy's ground objects. For peaceful purposes, energy of radiation can be transformed into electrical energy with the ^{and} help of solar batteries. If necessary, a spot beam following a spiral or any other prescribed trajectory, which depends on the voltage values generated by the quadrature generator ¹⁰⁸ ⁹ (Fig. ⁶), can intensify illumination of the surface like a floodlight.

To obtain a spherical specular surface (see Fig. 6), in addition to the first reflecting sheet 58 the second reflecting sheet 62 is used. Both reflecting sheets 58 and 62 are attached only to the pneumatic chambers 55, 56. They are not joined to the radial tubes. The internal 55 and external 56 pneumatic chambers together with the reflecting sheets 58, 62 make a sealed chamber, which is joined to the source of

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vacuum (vacuum pump) 63. Pressure created by the source of vacuum between the reflecting sheets in the chamber is lower, than that in the ambient outer space. Due to ~~exuberant~~^{an excess} external pressure, the specular sheets are attracted to each other and their surface receives ^a spherical form. The sag value h can be calculated beforehand and taken into account when fixing the sheets to the internal pneumatic chamber ⁷⁴ 55. The inner edges of the sheets are brought together relative to the plane for a distance of $2h$. If necessary, this spacing interval can also be changed within $0-2h$ $0-2h$ by a ~~remote~~ command from the Earth.

Electrostatic forces can be used to obtain a spherical specular surface and for remote modification of its radius of curvature.

For this purpose, the metal platings of the reflecting sheets ~~58, 62~~^{106 110} are connected to the ^{111 of emf} source (or voltage) ~~68~~¹⁹. By varying the voltage, it is possible to control the force of electrostatic attraction of the sheets, and by this to perform remote focusing of the ^{spherical} ¹⁹ mirror and to control ^{concentration} ~~focusing~~ of the luminous flux.

To create a spherical mirror, electrostatic forces and ~~excessive~~^{excess} external pressure can be simultaneously applied as well.

Employment of both specular surfaces is also possible, for which it is necessary to turn them through 180° .

In order a flat mirror could be transformed into a spherical one, the internal pneumatic chamber ⁷⁴ 55 should be made of two sections pneumatically attached to each other by ^{the} ⁸⁶ corrugated elastic band ⁹⁰ 67. The ^{third} pneumatic chamber ⁹¹ 68 joined to the source of compressed gas ⁷⁷ 61 by a separate gas ⁸⁶ ⁹⁰ ⁹¹ line (hose) ⁹⁰ 69 is installed inside this corrugated band. By varying pressure in the ^{third} pneumatic chamber ^{we one} can remotely change the interval between two sections of the internal pneumatic chamber within the limits ^{of} from 0 to $2h$. This is how the sag of the ^{second mirror} ¹⁹ spherical surface and the radius of its curvature are changed.

At Fig. 5 ⁸⁵ The corrugated band is topped with a ^{clamp} ⁸⁹ ~~yoke~~-shaped spring ⁷⁰, but it is possible ^{that} ^{be springy} for the band itself ~~to work as a spring~~.

Conditions

In the normal position, both sections of the internal chamber are pressed ⁷⁴ ~~to~~ ^{against} each other. With the start of gas delivery into the third pneumatic chamber ⁶⁸ ⁹⁰ inserted into the corrugated elastic band ⁸⁶ ^{the} ⁷⁴ sections of the internal pneumatic chamber ⁵⁵ move apart. At ⁹ definite pressure specular sheets ⁵⁸, ⁶² take the form of a plane. To prevent ~~from the further recession~~, there must be limiters fixed on both ^{106 110} ^{sections of the chamber 74 from further moving apart,} ¹¹⁰ ^{the} sides. A locating ring with end arresters ^{110 is provided with the} ^{Sensing} ⁸⁷ serves this purpose.

To give the specular surface of the sheet a regular spherical form, the second metal coating applied ^{to} ¹¹⁰ the second reflecting sheet ⁶² has the form of concentric rings ⁸⁷ ^{terminal of its own} ⁹. Each ring has an electrical ~~outlet~~ ⁹⁰ soldered to the metal bed.

By selecting the quantity, bandwidth and voltage applied to each ring, as well as the pressure in the third pneumatic chamber ⁶⁸, we can create specular surfaces of any configuration and curvature.

Depending on the problem to be decided, the ^{onboard} ~~on-board~~ computer by the ground command will change the voltage V_i on ^{the} ⁸⁷ ^{the} rings ⁶⁵ and ⁹⁰ pressure in the pneumatic chamber ⁶⁸.

For more effective employment of the system, in the daytime the second ¹⁹ large-size mirror can be used for a radio, television and telephone communication between ground objects. The mirror is used as a passive reflector. It is automatically established in the position that the normal \vec{n} to the ^{center} ~~centre~~ of the mirror should coincide with the "mirror - radio beacon" direction. In this case, the maximum of the directivity lobe of the transmitting antenna is pointed at the mirror. The system works more effectively if the transmitter has a narrow directivity lobe, as that for laser-beam communication. Radiation of the transmitter falls on the mirror and, having been reflected by it, returns to the Earth. Owing to angular divergence of the transmitter's radiation, radiation reflected by the mirror covers a greater area. With a corner reflector placed in front of the target seeker ^{23 (FIG. 3)} ~~TS₁~~ and the ^{of the type of the guidance device 5} transmitter installed on a satellite-tracking platform, the beam can be confined to several minutes of arc. Thus, the system can be used for laser beam communication ^{53 (FIG. 4)} between two ground objects, for which the second target seeker ^{53 (FIG. 4)} ~~TS₂~~ must keep

tracking the second ground object. To achieve this purpose, the ~~second~~ seeker ⁵³ ~~TS₂~~ in addition to an optical sensor is equipped ^{with} by radio-frequency range sensors designed similarly to those of the ~~first~~ seeker ⁴⁴ ~~TS₁~~.

In order to establish a directional two-way laser beam communication between two ground objects, both transmitters should be installed on tracking platforms, with their radiation directed towards ^{corner} corner reflectors placed in front of the corresponding target seekers ^{44; 53} ~~TS₁~~ and ~~TS₂~~. Within the frequency range the transmitters should operate at different frequencies to exclude interference.

Changing between operational modes of the system is done in response to the ground commands delivered through a radio circuit. For this, the system is equipped with a commutation unit ^{10(Fig.1)} EU, with the ^{aid} help of which the system is placed in one of four operational modes:

- a) directing the laser beam towards a target with the ^{aid} help of the ~~first~~ mirror (the ^I contact ^{55, 56, 36} of the ¹⁹ position of the switch ¹⁸); ³⁷
- b) one- or two-way communication between two ground objects with the ^{aid} help of the mirror ^{II} (¹⁹ the II position); ³⁷
- c) illumination of a ground object by radiation of its own transmitter (the III position) reflected by the mirror ¹⁹; ¹⁹
- d) illumination of a ground object by the solar radiation with the ^{aid} help of the second mirror ^{IV} (¹⁹ the IV position). ³⁷

For exploiting the system in the "a" mode, a radio beacon should be placed ⁹⁷ in the ~~center~~ ^{e.g.,} centre of a lighted ground object (a city). To reduce power of the radio beacon, the latter can be installed on a guidance device designed as ~~GD₁3~~ (see Fig.3).

The ~~first~~ guidance device ³ ~~GD₁3~~ is tracking the radio beacon ^A, while the ~~second~~ guidance device ⁴ ~~GD₂4~~ is intended for tracking the solar disk.

These guidance devices 3 and 4 (see Fig.3) permanently keep the radio beacon and the ^{center} ~~centre~~ of the solar disk on the optic axes of the corresponding target seekers ⁴⁴ ~~TS₁~~ and ⁵³ ~~TS₂~~.

Two signals, proportional to angular coordinates ~~of the target~~ ΔV_α and ΔV_β in two planes of control are shaped at the outputs of the guidance devices.

These signals go to the inputs of the corresponding subtracting amplifiers ~~SA₁~~⁶ ~~5~~ and ~~SA₂~~⁵ ~~6~~. The subtracting amplifiers compare coming signals and generate difference signals $\pm\alpha = \Delta V_{\alpha 1} - \Delta V_{\alpha 2}$ and $\pm\beta = \Delta V_{\beta 1} - \Delta V_{\beta 2}$. These difference signals go respectively to the ~~first and the second inputs~~^{inputs 9 and 14} of the commutation unit ~~CU~~¹⁰ ~~10~~.

The ~~third and the fourth inputs~~ of the commutation unit are connected to the corresponding outputs of the ~~first~~ guidance device 3. The ~~fifth and the sixth inputs~~¹⁰ of the commutation unit are connected respectively to the ~~third and the fourth outputs~~⁴ ~~of the second~~ guidance device. It is done in the way that the ~~first, second, third and fourth~~ output of the commutation unit¹⁰ are connected to the inputs of the corresponding actuators ~~A₁₇, A₁₈, A₁₁ and A₁₂~~^{20, 22, 46} ~~48~~ ⁴⁸ ~~51~~. The ~~fifth~~ output of the commutation unit¹⁰ is connected to the output of the ~~second~~ guidance device 4.

In the "b" mode the ~~third A₃ and the fourth A₄~~ actuators are kinematically coupled to ¹⁹ ~~connected with the second mirror~~ ¹⁹ ~~9~~. The second mirror ~~9~~ is used for aiming solar rays at a ground object (a city) in night-time. The same mirror can be used as a passive reflector for communication between any two ground objects and for radiotelephone space communication in mountain areas. In this case, the ~~second~~ mirror ~~9~~¹⁹ is automatically set perpendicularly to the optic axis of the ~~first~~ guidance device ~~GD~~³, which keeps tracking the radio beacon ~~X~~ placed in the ~~centre~~ of a lighted ground object (a city).

In the "c" mode the ~~first and the second~~ actuators are kinematically connected to ¹⁹ ~~with the first~~ mirror ~~9~~. This small-size mirror is placed in the ~~centre~~ of the coordinates, so that the ~~9~~ point should coincide with the ~~centre~~ of the mirror, and is used for aiming of a high-power laser beam. This mirror is made of beryllium bronze and cooled by liquid helium.

In the "d" mode of directing a laser beam towards an enemy's target, the latter is used as an object. The ~~second~~ guidance device ~~GD~~⁴ ₂ is aimed at the laser (radiation source 2). On the ~~third~~ guidance device ~~GD~~⁵ ₁₃ there is a laser, which

may be given the form of a cylinder whose axis (radiation) coincides with the optic axis of the ~~guidance device GD₃~~ target seeker. A light marker or a radio beacon, which is coaxially placed in front of the laser so that the latter might be better distinguished against the ground surface, ^{This} determines employment of optical or radar sensors (transducers) of the ~~second~~ target seeker ~~TS₂~~. The first, second and third output are the outputs of the radar sensor, while the fourth, fifth and sixth ones are the outputs of the optical sensor.

By the ground command the radio receiver ³³ with an aerial ~~Air~~ shifts a three-contact switch to one of the four positions (I, II, III, IV). Depending on the position of the switch, actuators ~~A₁, A₂, A₃, and A₄~~ receive signals from the outputs of the subtracting amplifiers or from the ~~third and the fourth~~ outputs of the ^{respective} ~~first~~ guidance device 3. Besides, the switch ¹⁸ connects the commutation output ⁵¹ of the ~~commutation unit~~ ⁵⁹ LU 10 with the output of the source of a unit signal (+V₁) ¹⁹ (position IV).

^{With the contacts 55, 56,} ³⁷ The switch ¹⁸ in the upper (I) position, the system works in the "a" mode. ⁶ ¹¹ The outputs of the subtracting amplifiers ⁸ and ⁸ through commutators ^{15, 16}, are connected, respectively, to the inputs of the ²⁰ ²² first and the second ^{central} ¹⁹ actuators ⁷ and ⁸. The system controls the ^{central} first metal mirror ⁹.

In this case, at the output of the commutation unit 10 there appears ⁵¹ ⁴⁵ a unit signal +V₁, which goes to the commutation input of the ~~second~~ guidance device ~~GD₂~~ 4.

In this case the system is used for aiming a powerful laser beam at the target. The source ² of radiation ⁸ (a laser) is installed on the ⁵ ~~third~~ guidance device ~~GD₃~~ 13. By reducing control signals to zero in ^{two} planes, the ⁵ ~~third~~ guidance device ⁵ 13 aims the laser at the light marker ⁶⁶ ^{comes} (or a corner reflector), placed in front of the target seeker ⁵³ of the ~~second~~ ⁴ guidance device ~~GD₂~~.

The ~~second~~ guidance device, in its turn, is aimed at a light marker (a radio beacon) placed in front of the ^{source (laser)} ^{laser} 2. When the output signals from the target seekers ⁵³ of the ~~second~~ ⁴ and the ~~third~~ ¹³ guidance devices become zero, their optic axes coincide, and the laser beam hits Point ⁰. After the error has been minimized,

44

3

the optic axis of the target seeker TS_1 of the first guidance device ~~GD₁~~⁴ comes to coincide with the direction " O - an object". Difference signals from the outputs of the subtracting amplifiers having been reduced to zero by the actuators A_{17} and A_{18} , the first mirror takes ^{6 and 11} ¹⁹ ^{a next} position, the normal \vec{n} in the Point O (origin of the coordinates) becomes a ^{bisector} bisectrix of the angle between optic axes of the target seekers of the ~~first and the second~~ guidance devices 3 and 4. The incident laser beam, ^{44 and 53} ^{after} having been reflected by the ~~first~~ mirror $9'$, hits the target 1.

To start a giant-pulse laser, an excitation pulse should be applied at the instant moment when the output signals of all target seekers of guidance devices TS_1 , TS_2 , ^{44 and 53} ^{3 4} ~~and 5~~ TS_3 , 3, 4, 13 and of the subtracting amplifiers 6 and 11 come to zero. The outputs of the subtracting amplifiers should be connected to the "I" element ^{AND gate 62} 20 provided with the NOT ⁶³ inverter ~~I~~ 21. A unit signal from the output of the inverter ^{63 excites} starts the laser. Information about zero values of the signal at the outputs of target seekers ^{44 and 53} and of the subtracting amplifiers may be transmitted through radio or laser commutation.

The middle position (II) of the switch corresponds to the zero value of the signal at the second inputs of the first ^{60, 61} ^{commutators 31 and 53} 15 and the second ^{6 and 11} ¹⁶ commutator. In this case, the outputs of subtracting amplifiers are switched to the inputs of the third A_3 and the fourth A_4 actuators, i.e. the system controls the second film mirror $9'$.

The second and the third contact of the switch 18 connect outputs of the commutators ^{31 53 to} ^{46 and 48} 18 and 16 with the inputs of the third and the fourth actuators. These actuators minimize error signals coming to the first inputs of commutators 15 and 53 from the outputs of subtracting amplifiers ~~SA₁ 5~~ and ~~SA₂ 6~~. By turning the second film mirror $9'$, the system can provide space communication between two ground objects, which have to be equipped with radio beacons. The first guidance device 3 is pointed to the object (radio beacon) 1, while the second guidance device 4, ¹⁹ to the second radio beacon. The second mirror $9'$ is automatically adjusted in such a way that a beam, radio-frequency radiation in the VHF or microwave range or a laser beam after having been reflected by the metal coating of the mirror $9'$ hits the second ground object and vice versa. With a view to secrecy the first ^{small} ~~small~~

mirror ¹⁹ can be used. This is how the space communication between two ground objects can be carried out.

With the switch ¹⁸ in the third (III) position, the unit signal $+V_1$ from the source output goes to the second inputs of the first and the second commutators ⁵¹, ⁵² and ⁵³ ^{60 and 61} ^{31 and 32}. ¹⁶ ^{which} makes them pass the signals from the third (V_3) and the fourth (V_4) outputs ^{15 and 16} ¹⁰ of the first guidance device ~~GD₁~~ 3, to the outputs of the commutation unit. These signals from the first and the second outputs of the target seeker ⁴⁴ ^{TS₁} of the first guidance device ~~GD₁~~ 3 go to the inputs of the third and the fourth ⁴⁴ ^{46 and 48} actuators which follow to indicate them. In this case the second mirror ¹⁹ becomes perpendicular to the optic axis of the first guidance device ~~GD₁~~ 3 directed towards the (radio beacon) ^{object 1}.

With the radio-controlled switch ¹⁹ in the fourth (IV) position, the system works in the "d" mode. In this case, the unit voltage $+V_1$ from the output of the unit ⁵¹ ⁵² goes to the fifth output of the commutation unit 10. This output is connected to the input of the second guidance device ~~GD₂~~ 4.

The fourth operation mode "d" demands that the second guidance device 4 should have a target seeker ⁵³ ^{TS₂} 32 (see Fig.4) with the sensors working within both the optical range (outputs 1,2,3), and the radio frequency band (outputs 4, 5, 6).

In comparison with the first ³ and the third ¹³ guidance devices (see Fig.3), the second guidance device ~~GD₂~~ 4 (see Fig.4) has the additional ⁵³ ^{59, 60, 61, 62 and 63} ^{3 and 5} ^{commutators} ^{the zero} ⁵³ ⁵⁹ ^{62 and 63} seventh, eighth and ninth commutator. With no unit signal at the commutation input ³⁷, the first, second and third outputs of the target seeker are connected to the corresponding inputs of the search signal conditioner ⁵³ ⁶⁰ ³¹ through commutators ³², ⁶⁰ ⁶¹ and ³⁴. Besides, the first and the second outputs of the target seeker ²³ are connected to the first inputs of the third ²⁹ and the fourth ³⁰ commutators through the eighth ³⁵ and the ninth ³⁶ commutators ^{64, 44}.

With the zero signal at the second inputs of these commutators ^{51 and 52}, the first and the second outputs of the ^{target seeker 44} ^{TS₂} 23 are connected respectively to the inputs ^{46 and 47} ^{actuators} ^{51 and 52} of the fifth ²⁵ and the sixth ²⁶ actuator. Thus, with a zero signal at the

commutation input of the ~~third~~ guidance device 4, it works in the same way as the ~~first 3 and the third 13~~ guidance devices (see Fig.3). ^{3 and 5}

In the lower position of the radio-controlled switch 18 a unit signal $+V_1$ goes to the commutation input ~~46~~ of the ~~second~~ guidance device 4. ³⁷

In this case, the fifth, sixth and ~~seventh~~ commutators ~~53, 38, 39, 40~~ let signals from the ~~corresponding~~ fourth, fifth and sixth outputs of the ~~TS₂ 32~~ pass to the input of the search signal conditioner (SSC₂) ~~45~~. ^{59, 60, 61}

At the same time, the ~~tenth 43 and the eleventh 44~~ commutators let signals from the fourth and the fifth outputs of the target seeker ⁵³ of the ~~second~~ guidance device 4 pass to the first inputs of the ~~eighth 41 and the ninth 42~~ commutators ^{62 and 63.} (see Fig.3a).

In this case the ~~radiosensors~~ of the ~~second~~ target seeker ~~32~~ of the ~~third~~ guidance device ~~GD₂ 4~~ work. ⁵³

Target seekers ~~TS₁ 23~~ of the ~~first 3 (and the third 13)~~ guidance devices ⁴⁴ ~~5~~ work in the radio-frequency range. ^{3 and 5}

As for the rest, principles of operation of guidance devices 3, 4, and ~~13~~ coincide. ⁵

If it is necessary to work in the optical range, guidance devices of the ~~GD₂~~ type ^{the} can be used, with a unit signal $+V_1$ given to the commutation input. ^{of those under Ref. No. 4}

The object 1 comes into the field of vision of the ~~first~~ guidance device ~~GD₂ 3.~~ ⁴⁴

When the object does not coincide with the optic axis of the ~~GD₂~~ target seeker, control signals at the ~~TS₁~~ output are different from zero. ^{of target seeker 44 other than}

Difference signals from the ~~TS₁ 23~~ go to the ~~fifth A₅ 25 and the sixth A₆ 26~~ actuators (servomotors) to be reproduced. The ~~first 72 and the second 73~~ brackets ^{46 and 47} together with the corresponding servomotors ^{46 47} ⁴⁴ turn the target seeker ~~TS₁~~ ^{target seeker 44} about the axes OX and OY. The optic axis of the ~~TS₁~~ is always directed towards the Point O, i.e., towards the ^{center} of the sphere, on which the target seeker ~~TS₁ 23~~ moves. Difference signals from the ~~TS₁~~ have been reproduced, the target seeker ~~TS₁ 23~~ takes such a position that its optic axis coincides with the direction towards ⁴⁴

the object (radio beacon) 1. When a system for lighting of an object is established on a mobile object, e.g., onboard a flight vehicle, it should be placed on a gyro-stabilized platform in order to provide gyroscopic decoupling. Angular position of the first target seeker TS_{123}^{44} with respect to the platform in two planes of control can be measured with the help of the first APP₁⁴⁷ and the second APP₂⁴⁸, angular position pickups (synchro transmitters or potentiometers).

For guiding a pencil-beam ~~aerial~~^{antenna} of the automatic direction-tracking system ADT the method of radio direction finding is used [4].

In the radio-frequency range, ADT_1^{44} and ADT_2^{53} are used instead of target seekers TS_1 and TS_2 .

A transmitting antenna of the radar station RS is placed in the ~~center~~^{center} of a lighted ground object (e.g., a city) and radiates electromagnetic waves into the ambient space. To reduce power of the ~~radio~~^{radio} automatic direction-tracking device (~~automatic direction-tracking system~~, the target seeker TS_{123}^{44}) ADT_{123}^{45} may be equipped with a corner reflector.

The corner reflector consists of three reflective plates adjusted perpendicularly to each other. In the corner reflector, incident energy from the radar station, having been two or three times reflected by ^{the} surfaces of the three plates, is reverted in the direction the radiation has come from. Thus, a small-sized corner reflector is capable ~~to create~~^{of creating} reflection of high intensity [4].

The transmitting ~~aerial~~^{antenna} of the radar station with the help of an automatic direction-tracking device ADT is oriented to the corner reflector and points electromagnetic waves ~~to~~^{thereto} it. The first automatic direction-tracking device ADT_1^{44} in turn, directs the axis of the first target seeker TS_{123}^{44} (which coincides with the ~~automatic direction-tracking device~~^{that is a first radar station}) towards the source of radiation, RS_1 .

The automatic direction-tracking devices ADT_1 and ADT_{123} can be designed to use the method of conical scanning of an ~~aerial~~^{antenna} beam or the monopulse measuring of angular coordinates; the latter guarantees a higher degree of accuracy and ~~allows of using~~^{permits to use} both pulse and continuous energy radiation [4].

It is known that with the first method used, deviation of an object from an equisignal direction is accompanied by the maximum beam alternately coming nearer to the object or receding ~~from it~~^{therfrom}. Owing to this, impulses of return signals are modulated in amplitude with a conical-scan frequency of the beam, while modulation depth depends on the value of the error. The curve, which turns tops of reflected pulses, is an error signal. The initial phase of the envelope curve depends on how far the object deviates from the equisignal position in azimuth and angle of elevation. Automatic tracking lies in automatic rotating of the ~~serial~~ axis until the error signal becomes zero. When error signals of the both ~~ADT~~ devices become zero, the equisignal lines of transmitting and receiving ~~serials~~ come to coincide and the axis of the ~~first~~ target seeker ~~TS₁~~⁴⁴ is now directed towards the radiating ~~aerial~~^{antenn^a} of the ~~first radar station~~^{cintenn^a}.

~~the RS-1~~

53

The ~~second~~ target seeker ~~TS₂~~³² is directed towards the Sun with the ~~help~~^{aid} of the ~~third~~^{95 and 94} and the ~~fourth~~⁷⁵ brackets and the corresponding seventh A₃₄ and the eighth A₃₅ actuators (servomotors) of the ~~second~~ guidance device ~~SD-4~~⁴ coupled thereto. kinematically attached to them. Angular position of the target seeker ~~TS₂~~^{53 with} in respect to the gyro-stabilised platform is measured by the ~~third~~ and the ~~fourth~~ angular position pickups ⁵⁷₃₆ and ⁵⁸₃₇ the target seeker ⁵³. When ~~TS₂~~ turns about the axes OX and OY, its own optic axis always goes through the origin of OXYZ coordinates.

CCD-rulers used in the target seeker for aiming at the Sun are not damaged if locally overlit and do not get out of order even at a thousandfold increase of a luminous flux in comparison with the flow of saturation. To increase noise immunity of the Sun seeker, CCD-rulers' lenses are ~~further~~ additionally equipped with optical filters, e.g., of the IRS-7 type, which transmit radiation only of the near-infra-red region, and with neutral filters, that diminish brightness of the solar disk image to required values.

the 44 53

Whichever position ^{the} target seekers ~~TS₁~~ and ~~TS₂~~ moving on the surface of the sphere may take, their optical axes intercross ^{at cent^r} in the ~~cent^r~~ centre of the O sphere.

The second mirror \mathcal{S}^1 is installed on a gimbal mount. The gimbal mount which consists of the internal \mathcal{G}^1 and the external \mathcal{G}^2 frame kinematically attached to the corresponding third A_1 , 11 and the fourth A_{12} actuators (servomotors) \mathcal{M}^1 and \mathcal{M}^2 , provides rotation of the mirror about the axes OY and OX.

To direct incident sun rays, which coincide with the optical axis of the \mathcal{TS}_1 , along the "O-target" line (coincident with the optic axis of the \mathcal{TS}_2), subtracting amplifiers (comparators) SA_1^5 and SA_2^6 are used.

The inputs of the first subtracting amplifier SA_1^5 are connected to the outputs of the first GD_1^3 and the second GD_2^4 guidance devices. In position I of the switch S^3 the outputs of the first subtracting amplifier SA_1^6 are connected to the inputs of the first actuators A_1^{11} . The A_1 provides rotation of the first mirror \mathcal{S}^1 about the OY axis. The first and the second inputs of the second subtracting amplifier SA_2^6 are connected respectively to the second outputs of the first GD_1^3 and the second GD_2^4 guidance devices. The output of the SA_2^6 is connected to the input of the second actuators A_2^{11} . The A_2 provides rotation of the mirror about the OX axis.

The subtracting amplifiers (comparators) \mathcal{S}^1 and \mathcal{S}^2 generate difference signals $\Delta U = U_1 - U_2$, where U_1 and U_2 are voltage values removed from two angular position pickups of the GD_1^3 and GD_2^4 (e.g., from potentiometers). Movable contacts of the potentiometers are kinematically attached to brackets, with the help of which the target seekers \mathcal{TS}_1 and \mathcal{TS}_2 are directed towards the object 1 and the radiation source 2. The subtracting amplifier is built around an operational amplifier. The difference signal ΔU at the output of the subtracting amplifier is proportional to the difference of the angles $\Delta\alpha$ (or $\Delta\beta$) in two planes of control (XOZ and YOZ). The difference signal $\pm\Delta U$ goes to the corresponding actuators A_1^{11} and A_{12}^{12} , which follow to indicate them and rotate the mirror about the OX and OY axes in order to reduce error signals to zero.

When the \mathcal{TS}_1 comes out of sight, the system goes into mode starts operating in the search operation. In this case, the inputs of the fifth and the sixth actuators A_5^{46} and A_6^{47}

~~through the third 29 and the fourth 30 commutators~~ are connected to the outputs of the search signal conditioner ~~SSC₁~~ 31. ~~50 through the commutators 51 and 52.~~

Similarly, with ^{the 2} source of radiation ~~2~~ out of sight of the second target seeker ^{3 and 4}, ~~32 of the second guidance device~~ ~~GD₂~~ 4, the inputs of the ~~seventh 34 and the eighth 55 and 56~~ ^{46 47 55 56} search signal conditioner ~~66~~ 66. ~~38~~ actuators are connected to the outputs of the ~~SSC₂~~ 45.

The search signal conditioners ~~SSC₁~~ 31 and ~~SSC₂~~ 45 of the guidance devices ~~GD₁, GD₂~~ shape two signals of ramp amplitude in phase quadrature ($\sin \varphi, \cos \varphi$). Having received such signals, the actuators ~~A₅ 25'~~ and ~~A₆ 26'~~ (34 and 35) rotate ~~TS₁~~ ^{target seeker 44(53)} ~~(TS₂)~~ about the OX and OY axes so that the optic axes of the target seekers are scanned along ^a the spiral sweep-trace.

When the Sun comes into the field of vision of the ~~second~~ target seeker, its ^{aid} ^{optoelectronic} radiation is registered with the help of ~~optical electronic~~ transducers of the ~~TS₂~~ 32.

Its outputs send sync pulses from the outputs of the synchronizing signal generator to ^{the 104} sync inputs of the ~~SSC₂~~, while the first 90 and the second 91 input of the ~~SSC₂~~ receive normalized signals coming from the outputs of the target signal detectors. Having received ~~the~~ both signals from the outputs of the target signal detectors, the system goes into the tracking operation. ^{The} Commutators ^{62 63 64 and 65} ~~actuators 55 and 56 to the outputs of the target seeker 44 of the guidance device 3.~~ connect inputs of the ~~A₇ and A₈ to the target seeker TS₂~~ 32 outputs of the ~~GD₂~~.

The search signal conditioners ~~(SSC₁)~~ 31 and ~~(SSC₂)~~ 45 work as described below (see Fig. 9).

If there is no target pulse in the interval between two successive sync pulses (at least at one of the ~~SSC₁~~ information inputs), then at the output of the logical unit (LU) ^{data} ~~set 101~~ there appears a level of the logical unit, which prevents recording new information in the devices of storage sampling ~~DSS₁~~ 84 and ~~DSS₂~~ 85 (operation of the logical set will be described below). At the ^{111 and 112} ¹¹² instant of changeover at the LU ^{of the logical unit 101} output from zero to one, that is, along the leading edge, the voltage at the output of the GLCV (generator of linearly changing voltage) ¹⁰⁵ ^{becomes equal} 79 steps down to zero and starts to ^{increasing} increase linearly (from zero).

generator 105

The output voltage of the GLEV modulates harmonic signals from the outputs of the quadrature generator 108 by means of modulators M₁ 106 and M₂ 107, with the signals at the generator 88 outputs 90-deg out of phase. This allows having harmonic signals of ramp amplitude in phase quadrature (sine and cosine) at the outputs of the amplitude modulators 80 and 81.

At the outputs of the first and the second summers 72 and 73 there appear voltage values equal to the sum of voltage values at the outputs of corresponding modulators 80 and 81 and DSS₁ 106 and DSS₂ 107, i.e., $U_{DSS_1} + U_{M_1} = U_{\Sigma 1}$, where U_{DSS_1} , U_{M_1} and $U_{\Sigma 1}$ are voltage values at the outputs of the DSS₁, modulator M₁ and the summer 110.

T analog-digital

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Similarly to $U_{DSS_2} + U_{M_2} = U_{\Sigma 2}$, the analog-to-digital converters ADC₁ 86 and ADC₂ 87 convert voltage at the outputs of corresponding summers 82 and 83 into a digital signal. If the SSC₁ and SSC₂ are required to produce analog-formed control signals in an analog form, the analog-to-digital converters ADC₁ 86 and ADC₂ 87 are not necessary.

Space scanning can be achieved by application of the signal from the outputs of the summers 82 and 83 (by means of ADC₁ 86 and ADC₂ 87, ADC₁ 86 and ADC₂ 87) to the fifth and the sixth (the seventh and the eighth) actuators of the guidance devices 3(4) GD₁ (GD₂), which provide rotation of the TS₁ 23 (TS₂ 32) in two mutually perpendicular planes about the OX and OY axes of the OXOY coordinate system connected with the gyro-stabilized platform. Position taken by the start of the spiral depends on the voltage values at the outputs of the DSS₁ 84 and DSS₂ 85, i.e., these values are proportional to the tangents of the angular coordinates.

If a radio beacon or the Sun comes into the field of view of the target seeker 44 (53) TS₁ 23 (TS₂ 32), the radiation is recorded with the help of detectors or optoelectric converters. In this case, at the outputs of the target detectors TD there appear pulses of target detection [3], which will assure the level of logical zero at the output of the logical unit 103. At this moment, instantaneous (current) voltage values are recorded at the outputs of the corresponding summers 82 and 83 along

of the logical unit 101 devices 111 and 112

the trailing edge of the LU 89 output in the DSS₁ 84 and DSS₂ 85, and zero voltage is provided at the GLCV output. As long as the target is in the beam path, the logical set will shape "I", thus providing zero voltage at the GLCV 79 output, while at the output of the summers 82 and 83 voltage remains the same, since the devices 111 and 112 DSS₁ 84 and DSS₂ 85 store the voltage values produced at the outputs of the summers 82 and 83 at the moment of "0" appearing at the LU 89 output (i.e. U_{DSS₁} = U_{Σ1}), and "0" at the GLCV output (i.e. U_{GLCV} = 0).

This is how the stationary position of the mirror 9 is obtained. When the target leaves the field of vision of the TS₁ 23 or (TS₂ 32), the level of the logical unit appears at the LU 89 output, the GLCV starts to produce ramp voltage, recording in the DSS₁ 84 and DSS₂ 85 is blocked and the process (spiral sweep) starts, the centre of the spiral being in the straight line, which crossed the target at the instant when the target was

the moment of its leaving the field of vision of the target seeker.

If there is no target in the field of view of the target seeker and the voltage at the GLCV output has reached some value assigned in advance and determined by the field of vision of the system, the GLCV resets the output voltage and the above-mentioned process starts anew.

The quadrature generator 88 can be designed as shown in Fig. 5.12, page 137 [7], the DSS as in Fig. 3.1, page 77 [7]. To prevent the DSS and the summers from inversion, they should be placed in series with inverters that have a unit gain factor equal to 1 (see Fig. 4.8."e", page 18 [7]).

The analog-digital converter (ADC) can be realised in a circuit design shown in the textbook "Linear integral circuits" by V.L.Shilo, "Sovetskoe radio" Publishers, Moscow, 1979, FIGS. 27, 24, 23, page 458 (in [6] (see Fig. 24, 23, page 458). Russian).

For modulators it is possible to use standard amplitude modulators, with their control inputs connected to the LU output and carrier frequency inputs, to the corresponding outputs of the quadrature generator.

The GLCV may be built around a standard generator of the saw-tooth growing voltage type.

In the above-mentioned shaper it is possible to use chips of the K153UD2, K161UD7, K161UD8, K140UD7, K140UD8, K154UD2 type, insulated-gate field-effect transistors, capacitors with a small loss tangent, etc.

The logical unit ¹⁰¹ ~~89~~ can be designed as shown in Fig. ¹⁰ ~~7~~. It ^{functions} ~~operates~~ as follows described below.

^{synchronizing} ~~at~~ ¹⁰³
A synchronising pulse, which has come to the input ~~91~~ through the inverter ^{117 and 118} ~~102~~, sets the first ~~97~~ and the second ~~98~~ flip-flops to zero along the trailing edge, since K155TM2 chip flip-flops, ^{based} ^{made use of herein, are switched} which are used here, switch at the changeover from "0" to "1".

^{Along} ~~On~~ the leading edge of the sync pulse, information from the above-mentioned ^{117 and 118} ~~117 and 118~~ flip-flops is copied into the ~~third~~ ^{119 and 120} ~~fourth~~ 100 flip-flops (these flip-flops are also based on the K155TM2 chips). The four flip-flops operate in this way because pulses that come to their sync inputs are out of phase.

The ~~first~~ ¹¹⁷⁽¹¹⁸⁾ ~~97~~ (or the ~~second~~ ~~98~~) flip-flop will be in the unit state ^{provided} given that within the current period between two successive sync pulses there is a circuit pulse from the corresponding target detector ~~(TD)~~ that comes to the input ~~90~~ ¹⁰² (~~102~~). Otherwise, the flip-flop stays in the zero state. After arrival of the sync pulse, this ¹¹⁹⁽¹²⁰⁾ information is copied into the third ~~99~~ (~~the fourth~~ 100) flip-flop.

Thus, a logical unit appears at the direct input of the ~~third~~ ¹¹⁹⁽¹²⁰⁾ ~~89~~ (~~the fourth~~ ~~90~~) flip-flop on condition that within the given period between two successive sync pulses there is an object pulse from the ^{output of the} corresponding target detector ~~(TS)~~ ^{output}; otherwise the signal takes the zero value.

The zero state of either of the two ~~99 and 100~~ flip-flops results in the level of a logical zero at the ~~LU~~ output. This is provided by the ^{119 and 120} ~~X~~ element ~~91~~, which ^{may} be based on a K155LI1 chip.

The inverters can be based on chips of the K155LN1 type.

In the systems for lighting of an object, it is possible to use gyroscopic, electromechanical or electrohydraulic actuators. The first ones seem preferable, as they are inertialess ^{this} [1]. In case the target seeker's axis deviates from the direction (cf. the textbook "Infrared systems", by L.Z. Krikunov and I.F. Usoltsev "Sovetskoe radio" Publishers, Moscow, 1968, pp. 157-239 (in Russian)).

required, correctional sensors, which are connected ~~with~~^{to} the axes of the frames and receive signals, ~~create~~^{develop} torques that make the gyro precess in the direction of the object.

By measuring ^{the} strength of current in windings of correlation sensors (the value of the moments) it is possible to determine projections of the angular velocity vector of the observing line on two mutually perpendicular directions [1]. Wipers of potentiometer transducers fixed on the rotation axes of the gimbal joint frames will help ^{and} to determine angular coordinates in respect to the platform, on which the gyroscope is installed. In this case, sensor cases should be rigidly attached to the platform [1]. ^{(cf. the textbook "Infrared Systems", by L.Z. Krikunov and I.F. Usoltsev "Sovetskoe radio" Publishers, Moscow, 1968, pp. 157-239 (in Russian).)} [Insert B] * ^{attached}

In electromechanical autotracking systems direct current engines [1] can be used as servomotors. Taking into account values and signs of output signals, servomotors correct misalignments between the target seekers' axes and the direction towards the object. Wipers of potentiometer transducers or synchro transmitters fixed on rotation axes of the frames of the coordination unit produce signals, which determine angular position of the target seekers in relation to the axis of the controlled object.

To obtain a signal proportional to angular velocity of the observing line, tachogenerators are used, kinematically ^{coupled} attached to the shafts of servomotors. The same tachogenerators can be used as elements of vanishing feedback. Information about the angular position and angular velocity of the servo drive's observing line is used for control of an object. Signals proportional to the angular position of the coordinators are received from potentiometers or synchro transmitters fixed on the rotation axes of the gimbal mount frames, while signals proportional to the angular velocity of the observing line come from resistors inserted into the windings circuit of correction torque motors of the gyroscopic drive or from tachogenerators, kinematically ^{coupled} attached to servomotors of the electromechanical drive.

In addition to automatic lighting of ground objects the system provides information about the angular position of the target in relation to the OZ-axis. For

INSERT B

Having stopped the wipers of potentiometer transducers on the axes of rotation of the frames of a gimbal unit, one can find the angular coordinates with respect to the platform on which the gyroscope is held in position. In such a case the casings of the transducers should be locked-in with the platform (cf. the textbook "Infrared systems", by L.Z.Kriksunov and I.F.Usoltsev "Sovetskoe radio" Publishers, Moscow, 1968, pp.157-239 (in Russian)).

this purpose, information about the angular position of a ground object is obtained from the outputs of the angular position pickups APP₁ 27 and APP₂ 28. The presentational system, in comparison with its prototype, allows automatic illumination of ground objects from space. It also permits to increase the accuracy of measuring angular coordinates of the target, since the beam is aimed at the center of the target image.

~~cf.~~ Subject bibliography

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2. I.I.Shumeiko (editor). *Astronautics and rocket dynamics*. Express information, № 43, Moscow, 1989, p.p. 27-34, (in Russian).
~~(cf. DE Application #A 3,412,0763)~~
3. Application in Germany, № 3412076. G01B-11/03. *A system for determination of two-dimensional coordinates of a light spot.*
~~US Pat. A<#3,946,233~~
4. Patent of USA, № 3946233. *A weapons system for detection and usage against fixed and moving targets.*
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~~(The textbook by A.G.Aleksenko, K.A.Kolombet, G.I.Starodub, "Application of precision analog IC"; "Sovetskoye radio" Publishers, Moscow, 1980)~~
7. A.G.Aleksenko, K.A.Kolombet., G.I.Starodub. *Application of precision analog IC*. Moscow, "Sovetskoye Radio" Publishing House, 1980.

Formula of the invention

Item 1. The system for lighting of an object includes a source of radiation, the first guidance device optically integrated with an object, and the first mirror, kinematically bound with the first and the second actuators. The system is

distinguished by the additional second guidance device, the first and the second subtracting amplifier, a commutation unit, the third and the fourth actuators, and the second mirror, kinematically bound with the third and the fourth actuators. Inputs of these actuators are connected to the corresponding outputs of the commutation unit, whose first and second input are connected to the outputs of the corresponding subtraction devices. The first and the second inputs of these subtraction devices are, in turn, connected respectively to the first and the second output of the first and the second guidance device, while the input of the second guidance device is connected to the fifth output of the commutation unit. The first and the second output of the commutation unit are connected to the corresponding actuators, its third and fourth input are connected to the corresponding outputs of the first guidance device, while the fifth and the sixth input respectively to the third and the fourth output of the second guidance device.

Item 2. The system for lighting of an object in accordance with Item 1 distinguished by the following: a commutation unit, which includes the first and the second commutator, the first radio receiver, a three-contact four-position radio-controlled switch, the first source of unit voltage, the first "I" element, the first inverter and a radio transmitter. The first and the third inputs of the first and the second commutator are, at the same time, respectively the first - fourth inputs of the commutation unit. The first and the third output of the commutation unit by a radio-controlled switch are connected to the output of the first commutator, the second and the fourth output – to the output of the second commutator, the fifth output, with the switch in the third position, - to the output of the unit voltage source. Besides, the second and the third contact of the switch in the second-fourth positions of the switch are paralleled; in the third position the output of the unit voltage source is connected to the paralleled second inputs of the first and the second commutator. Meantime, the first - sixth input of the "I" element are connected to the corresponding first - sixth input of the commutation unit, while the output of the "I" element is connected through the inverter to the radio transmitter.

Item 3. The system for lighting of an object in accordance with Item 1 distinguished by the following: the first (third) guidance device has the first target seeker, the fifth and the sixth actuators, the first and the second angular position pickup, kinematically connected with each other. Inputs of the angular position pickups serve, at the same time, as the corresponding first and second output of the guidance device, which, in addition, has the first search signal conditioner and the third and the fourth commutator. The first outputs of these commutators are connected respectively to the first and the second output of the target seeker, whose first, second and third output is connected to the corresponding inputs of the search signal conditioner. The first and the second output of the search signal conditioner are connected to the third inputs, while its third output - to the paralleled second inputs of the third and the fourth commutator, the outputs of which, are, in turn, connected to the corresponding inputs of the fifth and the sixth actuators.

Item 4. The system for lighting of an object in accordance with Item 1 and Item 2 distinguished by the following: the second guidance device has a target seeker equipped with a light marker (or a corner reflector), the seventh and the eighth actuators, the third and the fourth angular position pickups, whose outputs are at the same time the first and the second output of the guidance device, the fifth - eleventh commutators and the second search signal conditioner. The first inputs of the fifth, sixth and seventh commutator are connected to the corresponding first, second and third output of the target seeker, while the third inputs to the corresponding fourth, fifth and sixth output of the second target seeker. The first and the second output of the target seeker serve, at the same time, as the third and the fourth output of the guidance device. Besides, the second inputs of the abovementioned commutators are paralleled with the second inputs of the tenth and the eleventh commutator and serve as the commutation input of the guidance device, while the outputs of the fifth, sixth and seventh commutator are connected respectively to the first, second and third input of the second search signal conditioner, whose first and second output are connected respectively to the third inputs of the eighth and the ninth

commutator. The second inputs of these commutators are paralleled and connected to the third output of the second search signal conditioner, with the first inputs of the eighth and the ninth commutator connected respectively to the outputs of the tenth and the eleventh commutator, the first inputs of which are connected to the first and the second output of the second target seeker, while their third inputs are connected respectively to its fourth and the fifth output.

Item 5. The system for lighting of an object in accordance with Item 4 distinguished by the following: a laser installed in the third guidance device serves a source of radiation. The laser is connected to the laser excitation circuit, the first and the second input of which are connected to the third and the fourth output of the third guidance device.

Item 6. The system for lighting of an object in accordance with Item 5 distinguished by the following: the laser excitation circuit includes the second radio receiver, a remote switch, connected to the second source of the unit signal, and connected in series the second element "I", an inverter and the third element " I_8 ", the second input of which is connected through the remote switch to the source of unit voltage, while its output is at the same time the output of the third "I" element. Besides, the first and the second input of the second "I" element serve at the same time as inputs of the excitation system and are connected respectively to the third and the fourth output of the third guidance system.

Item 7. The system for lighting of an object in accordance with Item 3 distinguished by the following: the search signal conditioner includes a logical unit, the output of which is connected to the reset input of a linearly changing generator and to the paralleled record permitting inputs of the first and the second storage sampling device. The outputs and information inputs of the storage sampling devices are connected respectively to the first inputs and outputs of the first and the second summer; the second inputs of the summers are connected respectively to the outputs of the first and the second modulators, whose first inputs are paralleled and connected to the output of the linearly changing voltage generator. The second

inputs of the first and the second modulators are connected respectively to the first and second output of the quadrature oscillator. Besides, outputs of the first and the second summer are connected respectively to the inputs of the first and second analog-to-digital converter, while inputs and the output of the logical unit together with outputs of the analog-to-digital converters are respectively the inputs and outputs of the controlling signal conditioner.

Item 8. The system for lighting of an object in accordance with Item 1, Item 2, and Item 7 distinguished by the following: the first guidance device, optically bound with an object, is equipped with the first target seeker kinematically attached through the first and the second bracket to the fifth and the sixth actuators and respectively to the first and the second angular position pickup. The second guidance device, optically bound with the source of radiation, includes the second target seeker, kinematically attached through the third and the fourth bracket with the seventh and the eighth actuators and the third and the fourth angular position pickup. The first mirror kinematically attached to the first actuators is fixed on the internal frame of the first gimbal mount, the external frame of which is kinematically attached to the second actuators. The system also includes the second gimbal mount, which consists of the internal and external frame kinematically bound respectively to the third and the fourth actuators. The external frame of the second gimbal mount is joined to the concentric ring, on which the second mirror is fixed.

Item 9. The system for lighting of an object in accordance with Item 1 distinguished by the following: the second mirror is made in the form of two rings concentric on the outer ring of the gimbal mount and on the attached to it the internal and external pneumatic chamber pneumatically joined by radial tubes to each other and to the source of compressed gas (air). The pneumatic chambers and the radial tubes are connected with a reflecting sheet, which consists of an elastic dielectric film, coated with a light reflecting metal cover (e.g., aluminium).

Item 10. The system for lighting of an object in accordance with Item 9 distinguished by the following: the second mirror has an additional second reflecting sheet, which is adjusted at a fixed distance from the first one, with the metal layers of the sheets connected to the opposite poles of the re-introduced emf source.

Item 11. The system for lighting of an object in accordance with Item 9 distinguished by the following: the first and the second reflecting sheet together with the internal and external pneumatic chamber create a hermetically sealed cavity of reduced pressure attached to a re-introduced source of vacuum.

Item 12. The system for lighting of an object in accordance with Item 10 distinguished by the following: the internal pneumatic chamber consists of two pneumatically integrated sections joined by a corrugated elastic band in order they could move relative to each other. The metal coating of the second reflecting sheet is made in the form of concentric rings isolated from each other and connected to different controlled voltage sources.

~~The abstract~~

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The invention deals with navigational engineering, specifically, optical-electronic systems for autotracking of moving objects.

The purpose of the presentational invention consists in diversifying functions of a target seeker by enabling it to search for a ground target and to light it from the outer space.

The implementation of this invention will technically result in more precise measuring of angular coordinates of the target because now the beam is pointed at the centre of the target image.

This technical result is achieved owing to some elements installed in the first device of the object guidance, such as an additional second guidance device optically connected with the radiation source, the first and the second subtracting amplifier, the first and the second actuator and a mirror. The first outputs of the first and the second guidance device are connected to the corresponding inputs of the first subtracting amplifier, while the second outputs to the corresponding inputs of the second subtracting amplifier. The outputs of the first and the second subtracting amplifier are connected to the inputs of the corresponding actuators kinematically linked to the mirror.

The commutation unit includes the first and the second commutator, a radio receiver, a three-contact four-position radio-controlled switch, a source of unit voltage, an "I" element, an inverter and a radio transmitter - all appropriately connected to each other.

The first and the third guidance device is of identical circuit design and actuates electrically linked to each other the target seeker (TS), the search signal conditioner (SSC), the first and the second angular position pickup (APP₁, APP₂), commutators, the third and the fourth actuators (A₃, A₄), kinematically linked with a target seeker, and the angular position pickups.

The second guidance device has a target seeker equipped with a light marker (or a corner reflector), the fifth and the sixth actuators, the first and the second angular position pickup, whose outputs are at the same time the first and the second output of the guidance device, the third - ninth commutators and a search signal conditioner with the corresponding connections.

The laser excitation circuit includes the second radio receiver, a remote switch, connected to the second source of a unit signal, and connected in series the second element "I", an inverter and the third element "I", the second input of which is connected through the remote switch to the source of unit voltage, while its output is at the same time an output of the third "I" element. Besides, the first and the second input of the first "I" element serve at the same time as inputs of the excitation system, which are connected to the third and the fourth output of the third guidance system.

The mirror is made in the form of two rings concentric on the outer ring of the gimbal mount and on the attached internal and external pneumatic chamber pneumatically joined by radial tubes to each other and to the source of compressed gas (air). The pneumatic chambers and the radial tubes are connected with a reflecting sheet, which consists of an elastic dielectric film, coated by a light reflecting metal cover (e.g., aluminium).

In the second variant, the mirror has an additional second reflecting sheet, which is adjusted at a fixed distance from the first one, with the metal layers of the sheets connected to the opposite poles of the re-introduced emf source.

The internal pneumatic chamber consists of two pneumatically integrated sections joined by a corrugated elastic band in order they could move relative to each other. The metal coating of the second reflecting sheet is made in the form of concentric rings isolated from each other and connected to different controlled voltage sources.

INSERT C

ABSTRACT OF THE DISCLOSURE

A system for lighting an object has a radiation source, a first guidance device optically connected to the object, a second guidance device and a first subtracting amplifier in communication with the first guidance device. The first subtracting amplifier has inputs and at least one output. A second subtracting amplifier is in communication with the first and second guidance devices. A commutation unit is in communication with the first and second guidance devices and the first and second subtracting amplifiers. First, second, third and fourth actuators are in communication with the commutation unit. A first mirror is in communication with and controlled by the first and second actuators and a second mirror is in communication with and controlled by the third and fourth actuators. The first and said second mirrors are controlled by the actuators so that the system can light an object by reflecting the radiation source.